In the claims:

Please amend the claims as follows:

1-20 (canceled)

21. (currently amended) An industrial robot operative to position a movable element in relation to a fixed element, comprising:

three driving means each comprising rods arranged in multi-join systems including three-axle ball and socket joints and each driving one link device arranged between the fixed element and the movable element ~~at least one linkage device comprising pull rods; and~~

~~a multi-joint system operatively connected to the linkage device, the multi-joint system comprising a plurality of three-axle ball and socket joints~~, each joint comprising a joint ball and a joint socket, the joint socket enclosing the joint ball with a space that comprises approximately one-half the ball or less, the joint socket further comprising a housing and at least one removable polymeric annular bearing member arranged in the housing, the bearing member comprising a bearing surface engaging at least a portion of a distal half of each joint ball and at least a portion of a proximal half of each joint ball, the housing comprising a surface against which a side surface of the at least one bearing member abuts, the surface comprising a plurality of friction-increasing grooves extending in a longitudinal direction of the surface, the grooves engaging and deforming the side surface of the at least one bearing member and being operative to increase friction between the at least one bearing member and the housing to rotationally immobilize the at least one bearing member in the housing during operation of the driving means.

22. (currently amended) The industrial robot according to claim 21, wherein the ~~industrial robot comprises a delta robot~~ the joint socket encloses at least a portion of the distal half of the joint ball and at least a portion of the proximal half of each joint ball.

23. (previously presented) The industrial robot according to claim 21, wherein the grooves are aligned at an angle with respect to a longitudinal axis of the bearing member.

24. (previously presented) The industrial robot according to claim 21, wherein the grooves comprise pointed tops.

25. (previously presented) The industrial robot according to claim 21, wherein the side surface of the at least one bearing member comprises a plurality of grooves extending in a longitudinal direction of the side surface and compatible with the grooves in the housing.

26. (previously presented) The industrial robot according to claim 21, wherein the grooves penetrate and permanently deform the bearing member.

27. (previously presented) The industrial robot according to claim 21, wherein the housing and the bearing member each have a socket shape, wherein a spring force holds the ball and socket joint together and fixes the bearing member in place.

28. (previously presented) The industrial robot according to claim 21, wherein the at

least one bearing member is pressed to fit tightly in the housing.

29. (currently amended) A method for forming an industrial robot operative to position a movable element in relation to a fixed element, the method comprising:

providing ~~at least one~~ three linkage ~~device~~ devices each comprising pull rods;

providing three driving means, each driving one of the linkage devices;

providing a multi-joint system comprising a plurality of three-axle ball and socket joints, each joint comprising a joint ball and a joint socket;

providing the joint socket enclosing the joint ball with a space that comprises approximately one-half the ball or less;

providing the joint socket with a housing a side surface comprising a plurality of friction-increasing grooves extending in a longitudinal direction of the surface; and

arranging at least one removable polymeric annular bearing member comprising a bearing surface in the housing, such that the bearing member engages at least a portion of a distal half of each joint ball and at least a portion of a proximal half of each joint ball and such that a side surface of the at least one bearing member abuts against the side surface of the housing and the grooves engage and deform the side surface of the at least one bearing member and increase friction between the at least one bearing member and the housing to rotationally immobilize the at least one bearing member in the housing during operation of the driving means.

30. (previously presented) The method according to claim 29, wherein the method fixes a location of the bearing member in the robot.

31. (currently amended) The method according to claim 29, wherein the ~~industrial robot comprises a delta robot~~ the joint socket encloses at least a portion of the distal half of the joint ball and at least a portion of the proximal half of each joint ball.

32. (previously presented) The method according to claim 29, wherein the grooves are aligned at an angle with respect to a longitudinal axis of the bearing member.

33. (previously presented) The method according to claim 29, wherein the grooves comprise pointed tops.

34. (previously presented) The method according to claim 29, wherein the side surface of the at least one bearing member comprises a plurality of grooves extending in a longitudinal direction of the side surface and compatible with the grooves in the housing.

35. (previously presented) The method according to claim 29, wherein the grooves penetrate and permanently deform the bearing member.

36. (previously presented) The method according to claim 29, wherein the housing and the bearing member each have a socket shape, wherein a spring force holds the ball and socket joint together and fixes the bearing member in place.

37. (previously presented) The method according to claim 29, wherein the at least one bearing member is pressed to fit tightly in the housing.